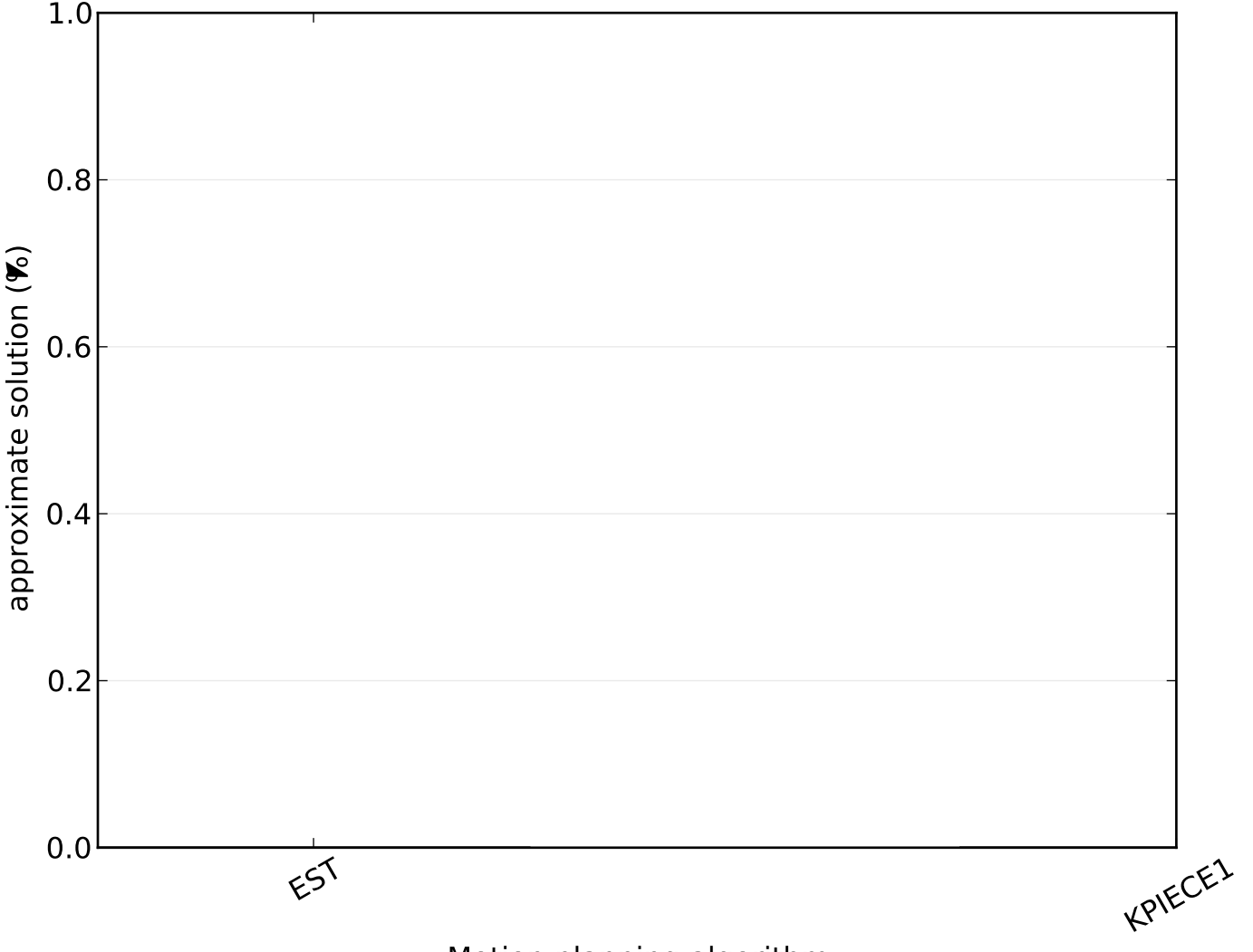
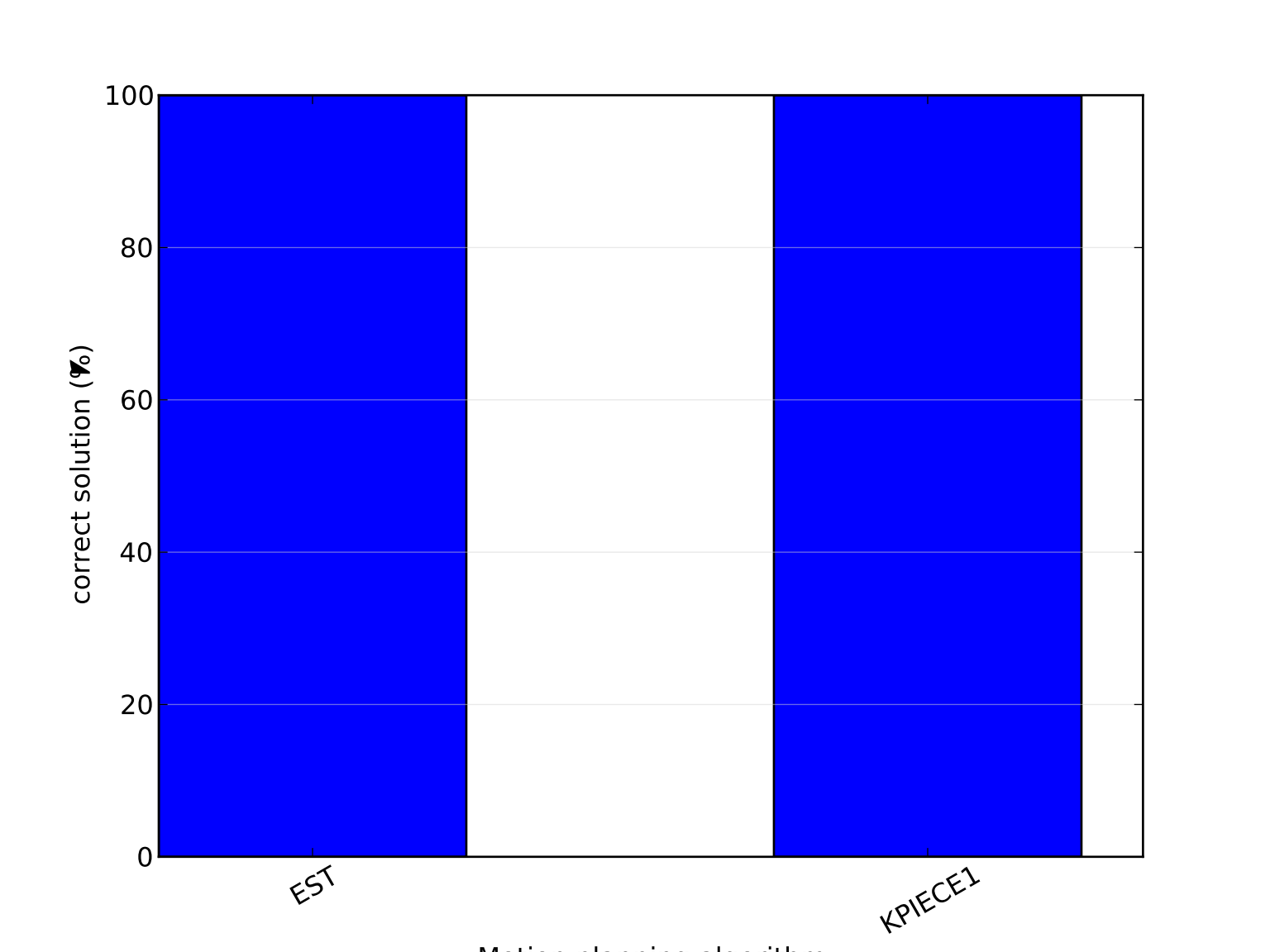
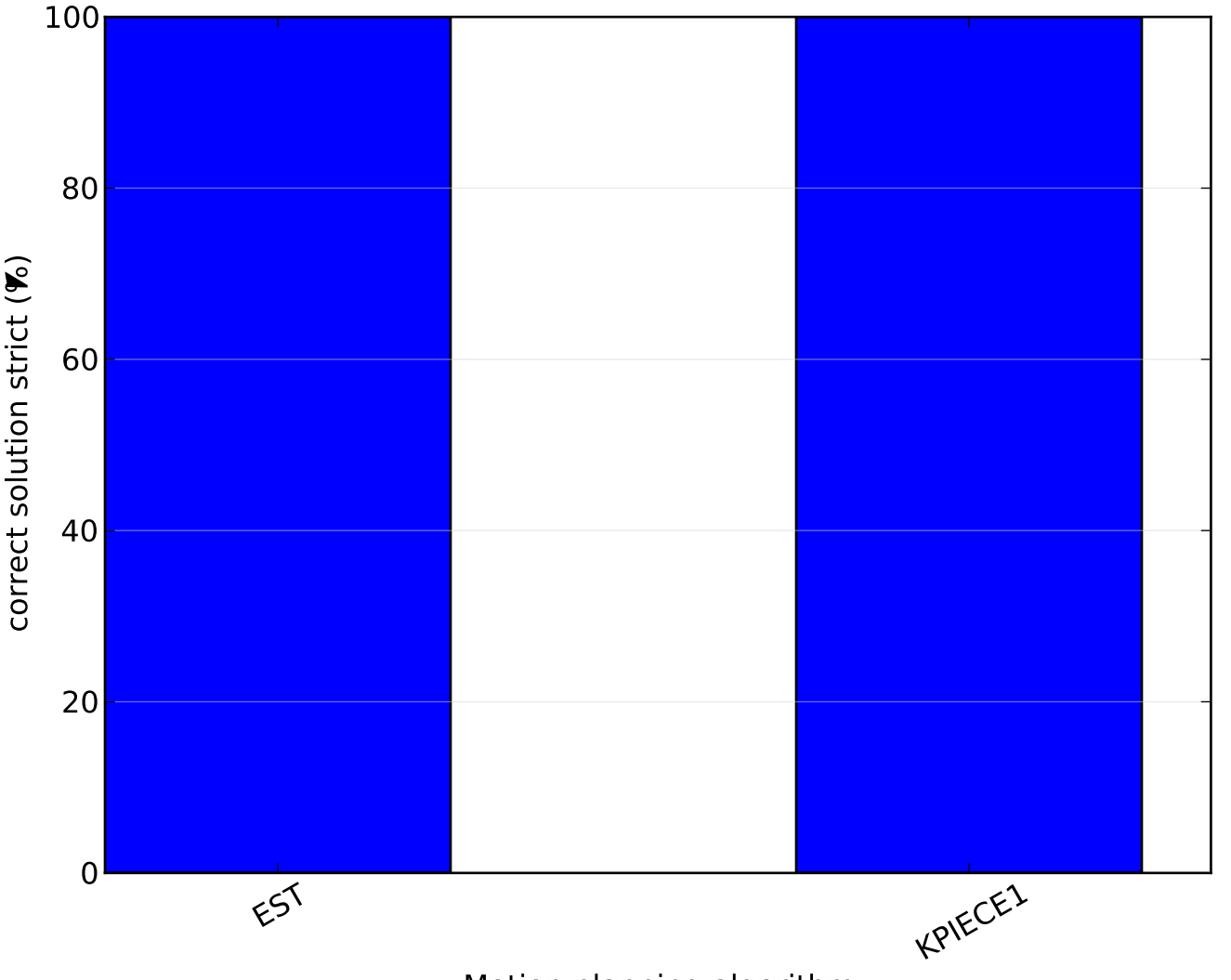
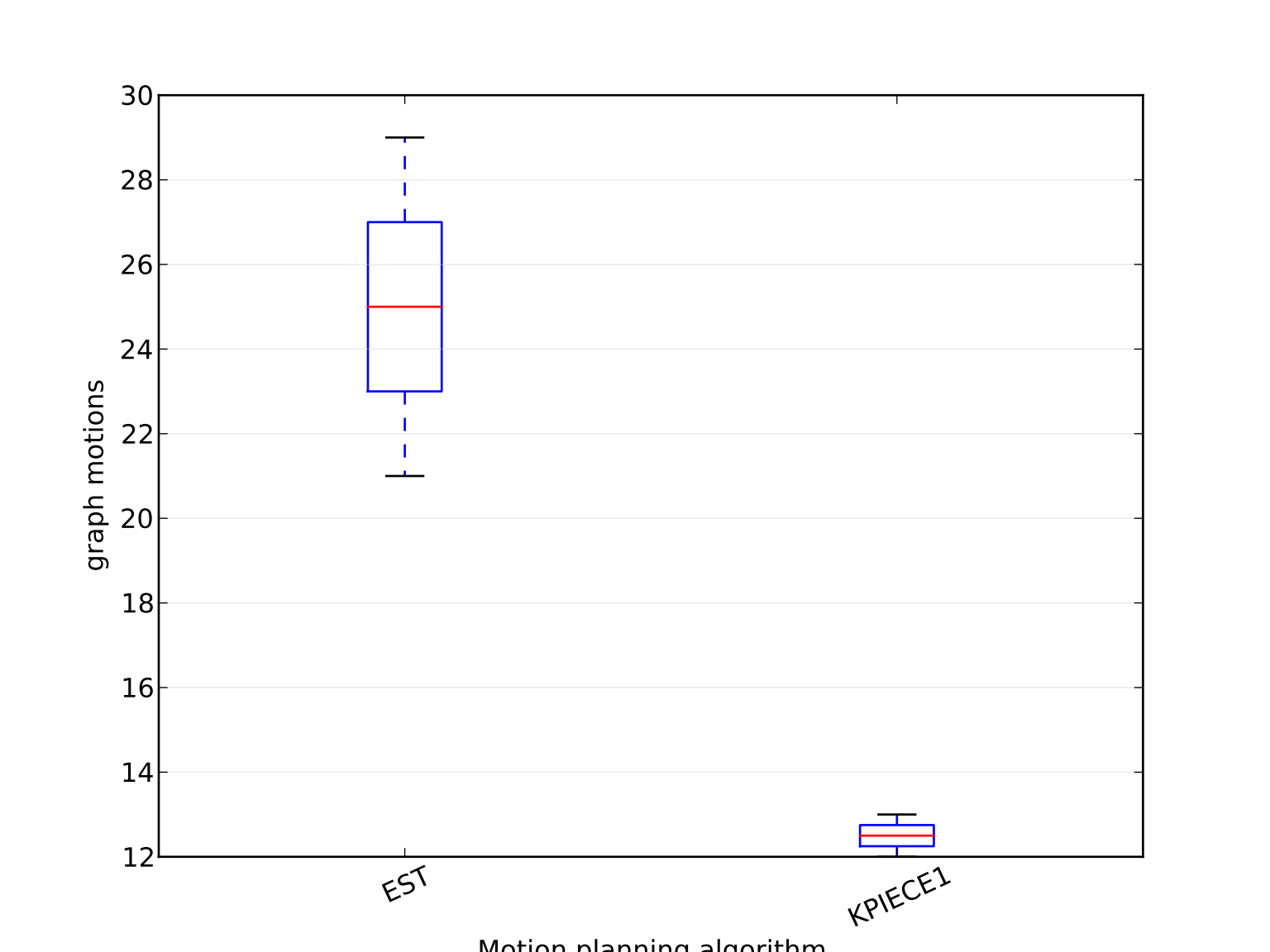
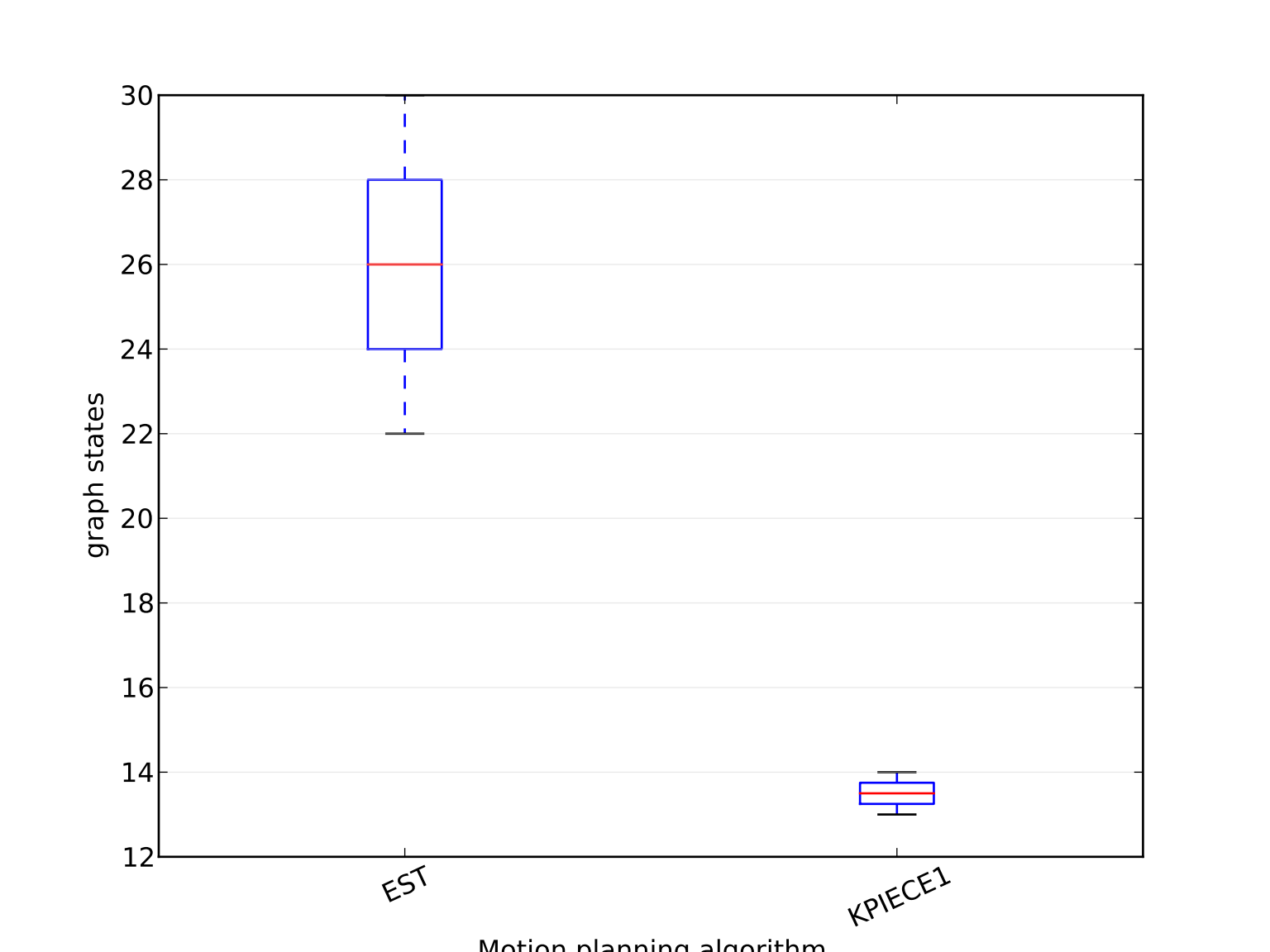
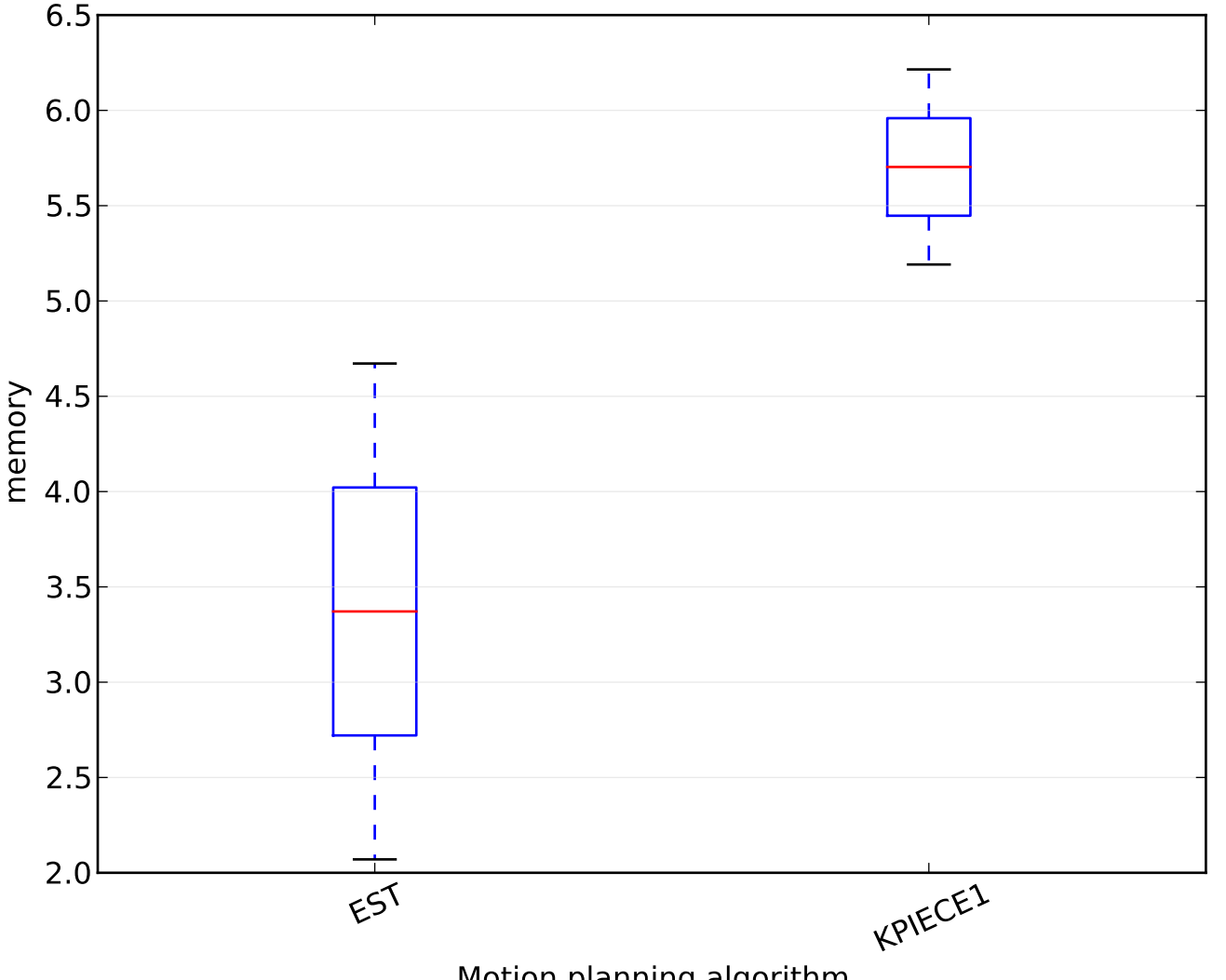

1.0
0.8
0.6
0.4
0.2
0.0
approximate solution (%)
EST
KPIECE1

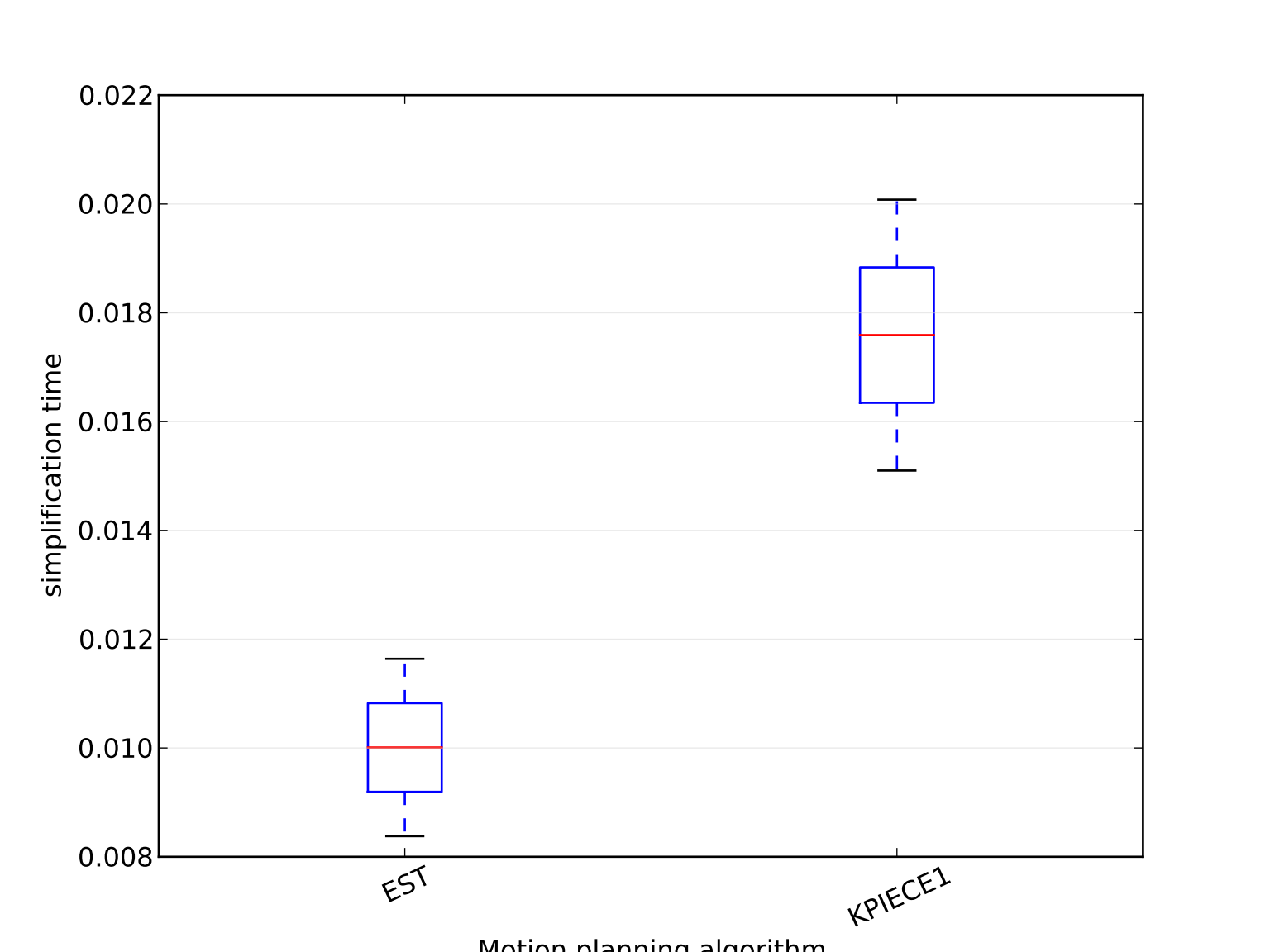

100
80
60
40
20
0
correct solution (%)
EST
KPIECE1

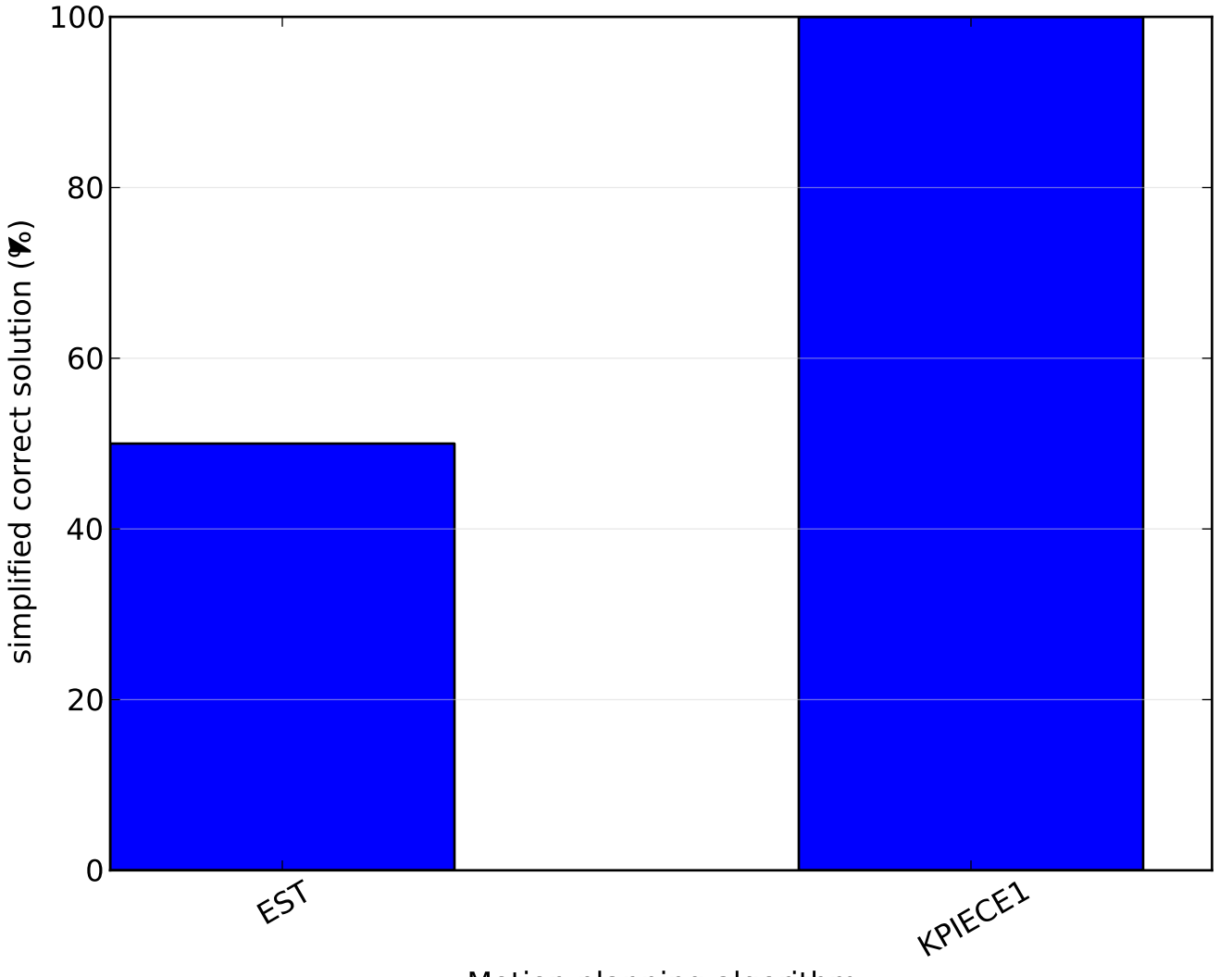

100
80
60
40
20
0
correct solution strict (%)
EST
KPIECE1

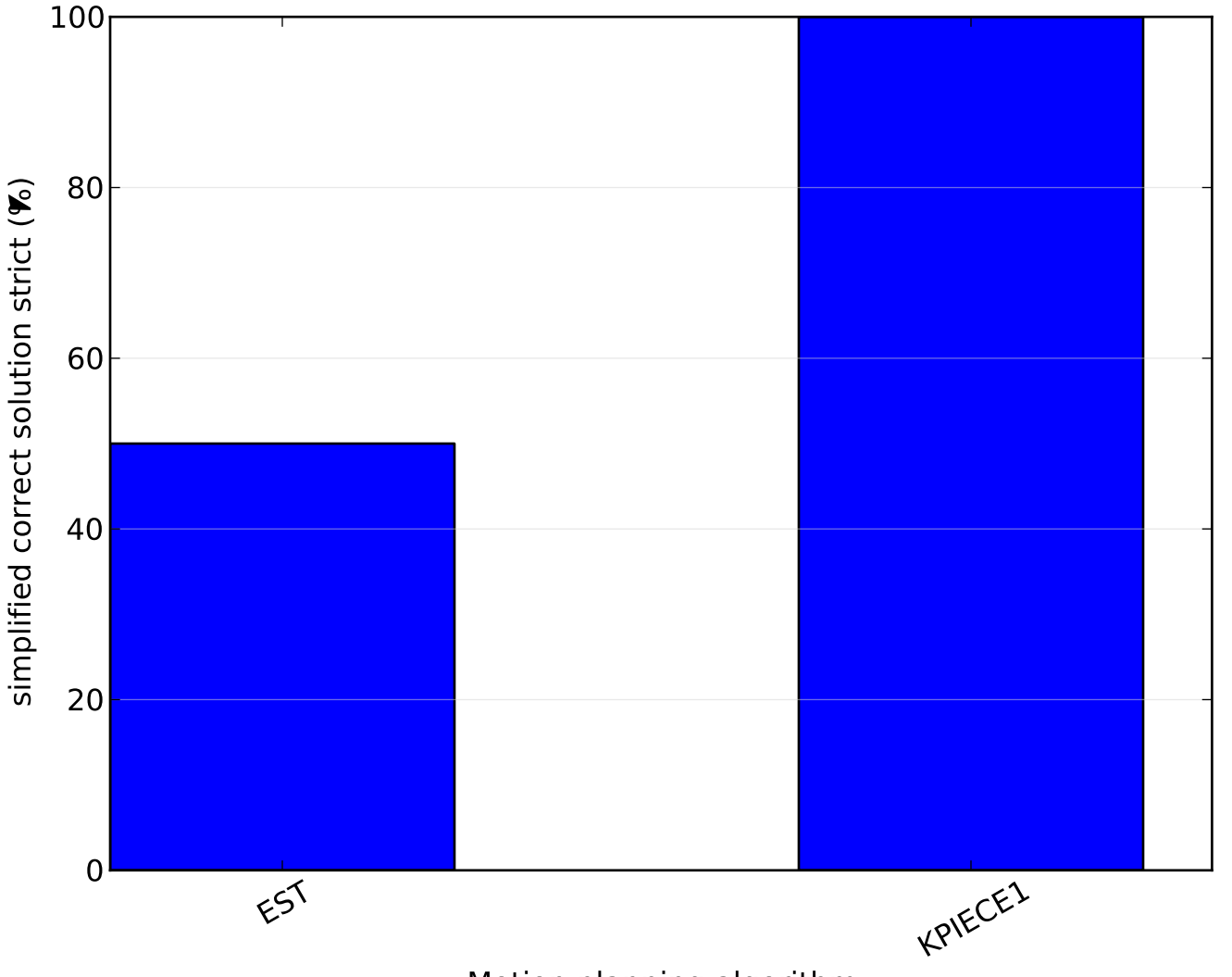

30
28
26
24
22
20
18
16
14
12
graph motions
EST
KPIECE1
Motion planning algorithm

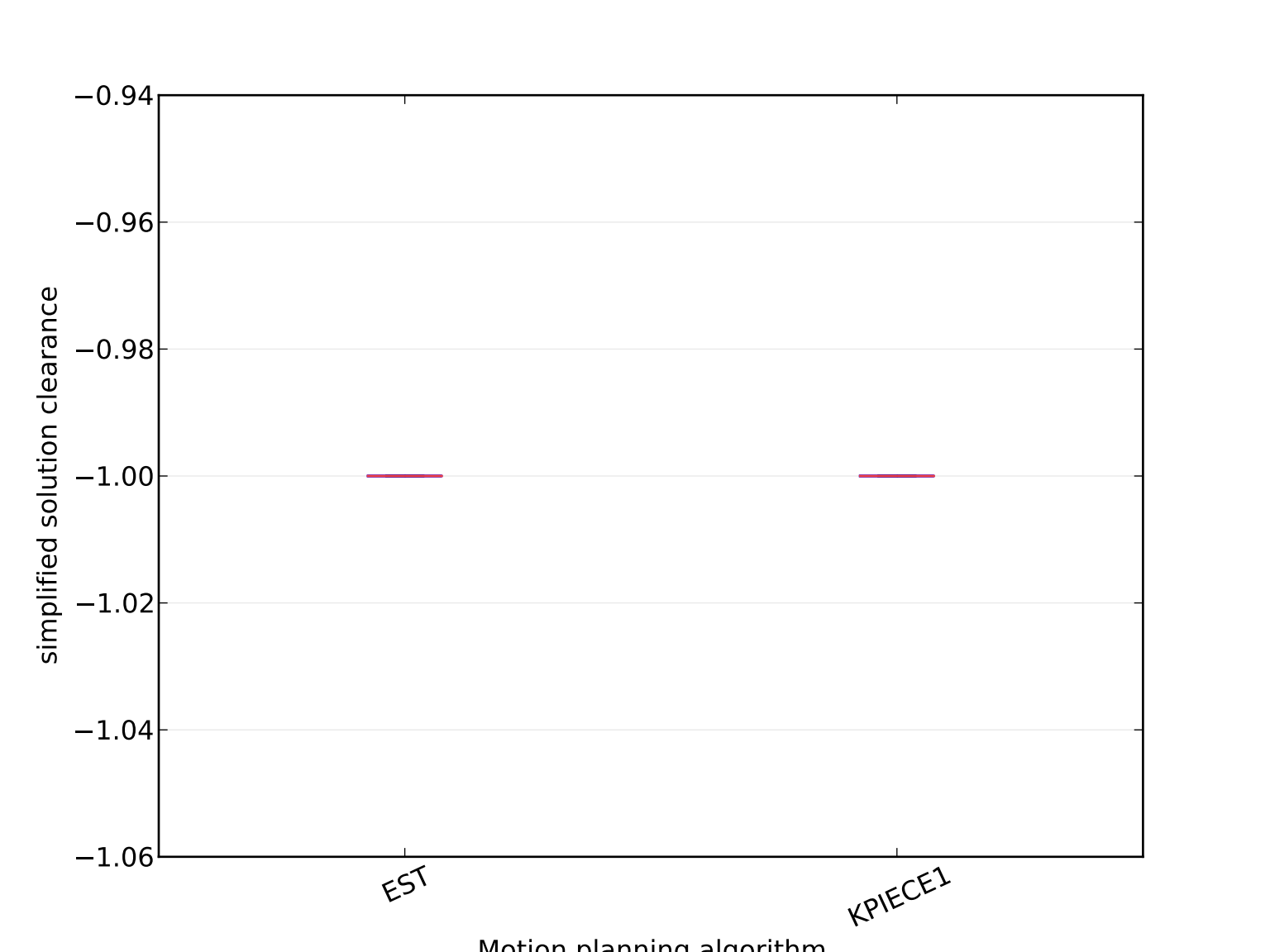

30
28
26
24
22
20
18
16
14
12
graph states
EST
KPIECE1
Motion planning algorithm

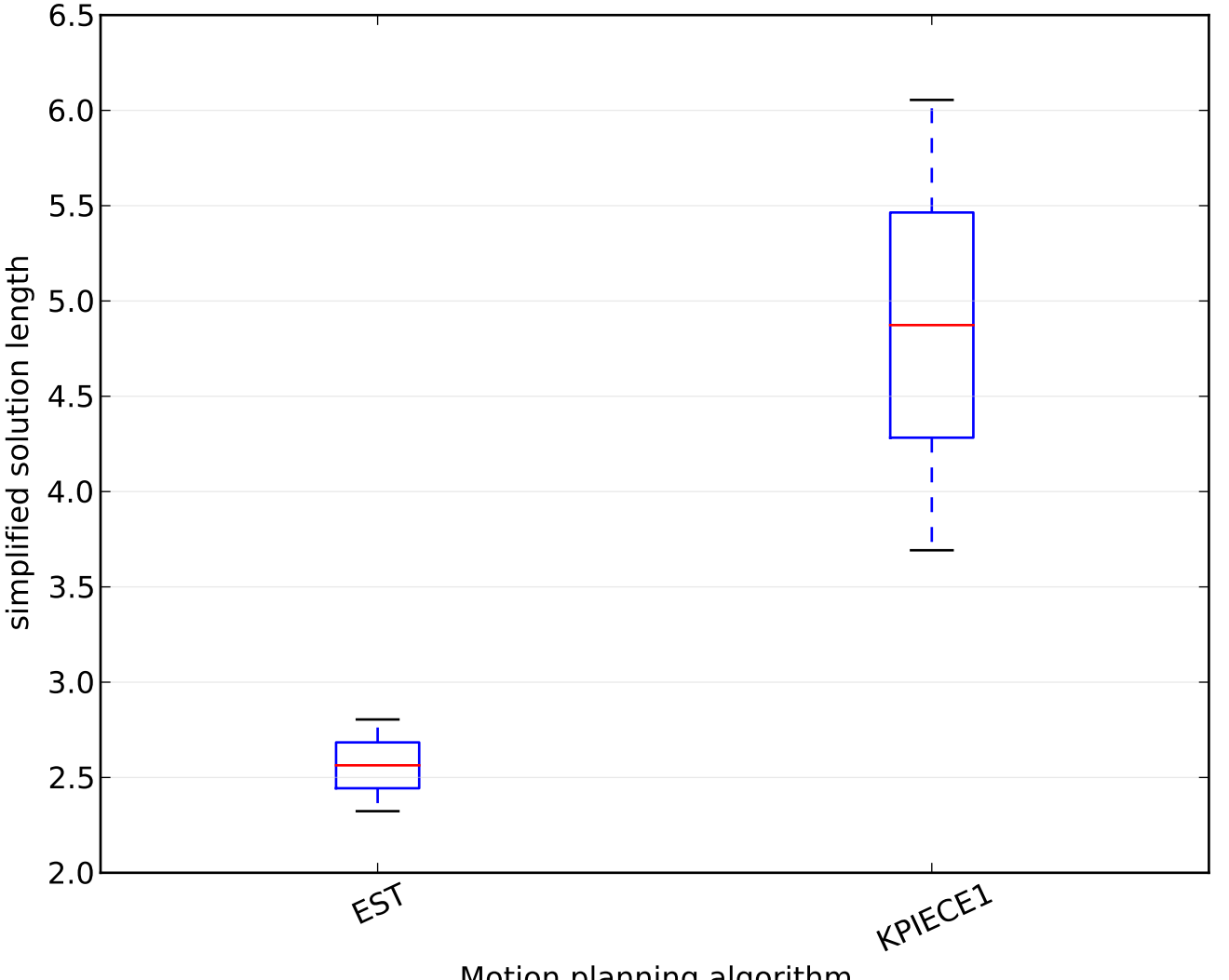

6.5
6.0
5.5
5.0
4.5
4.0
3.5
3.0
2.5
2.0
memory
EST
KPIECE1
Motion planning algorithm

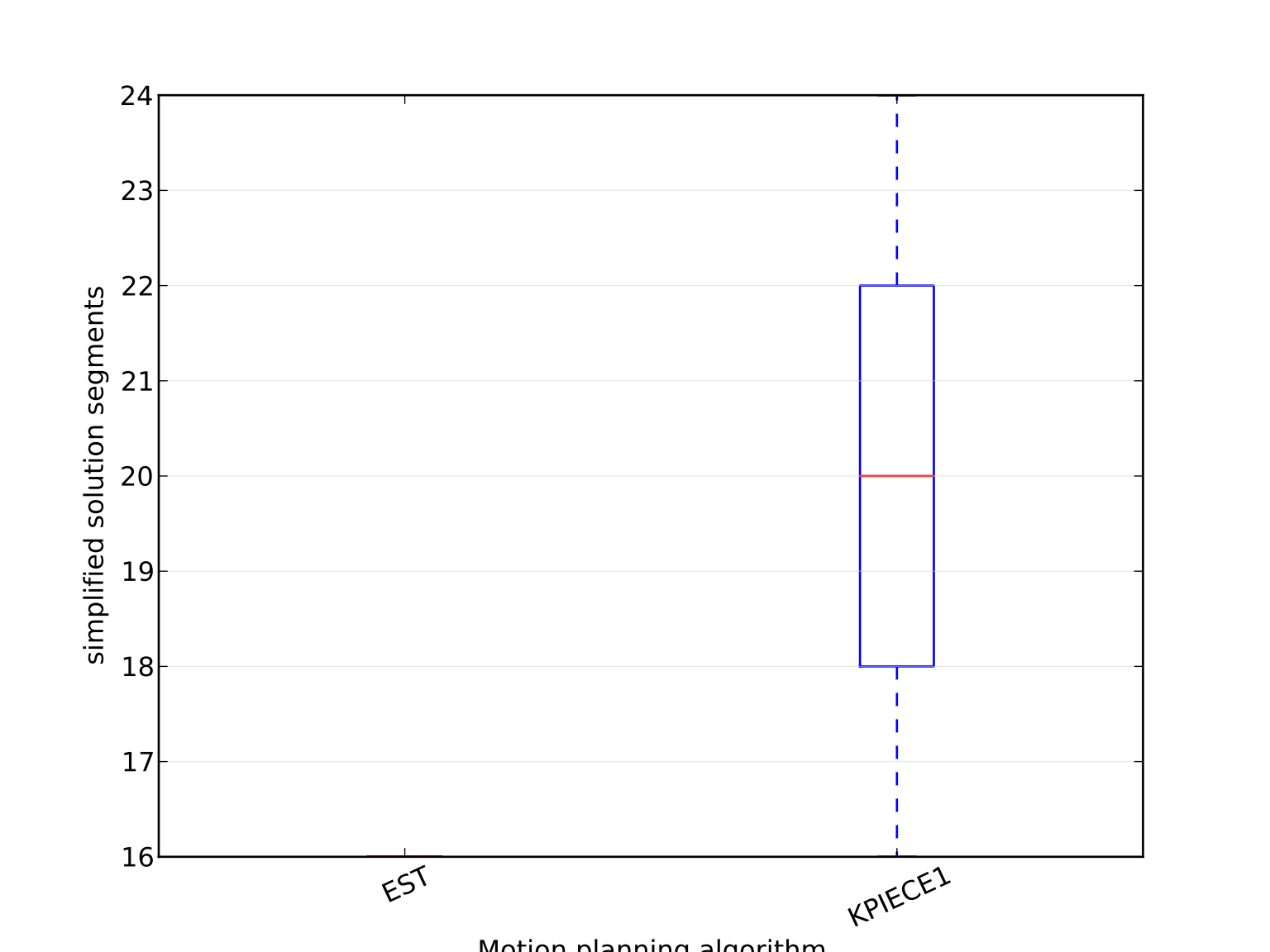

0.022
0.020
0.018
0.016
0.014
0.012
0.010
0.008
simplification time
EST
KPIECE1
Motion planning algorithm

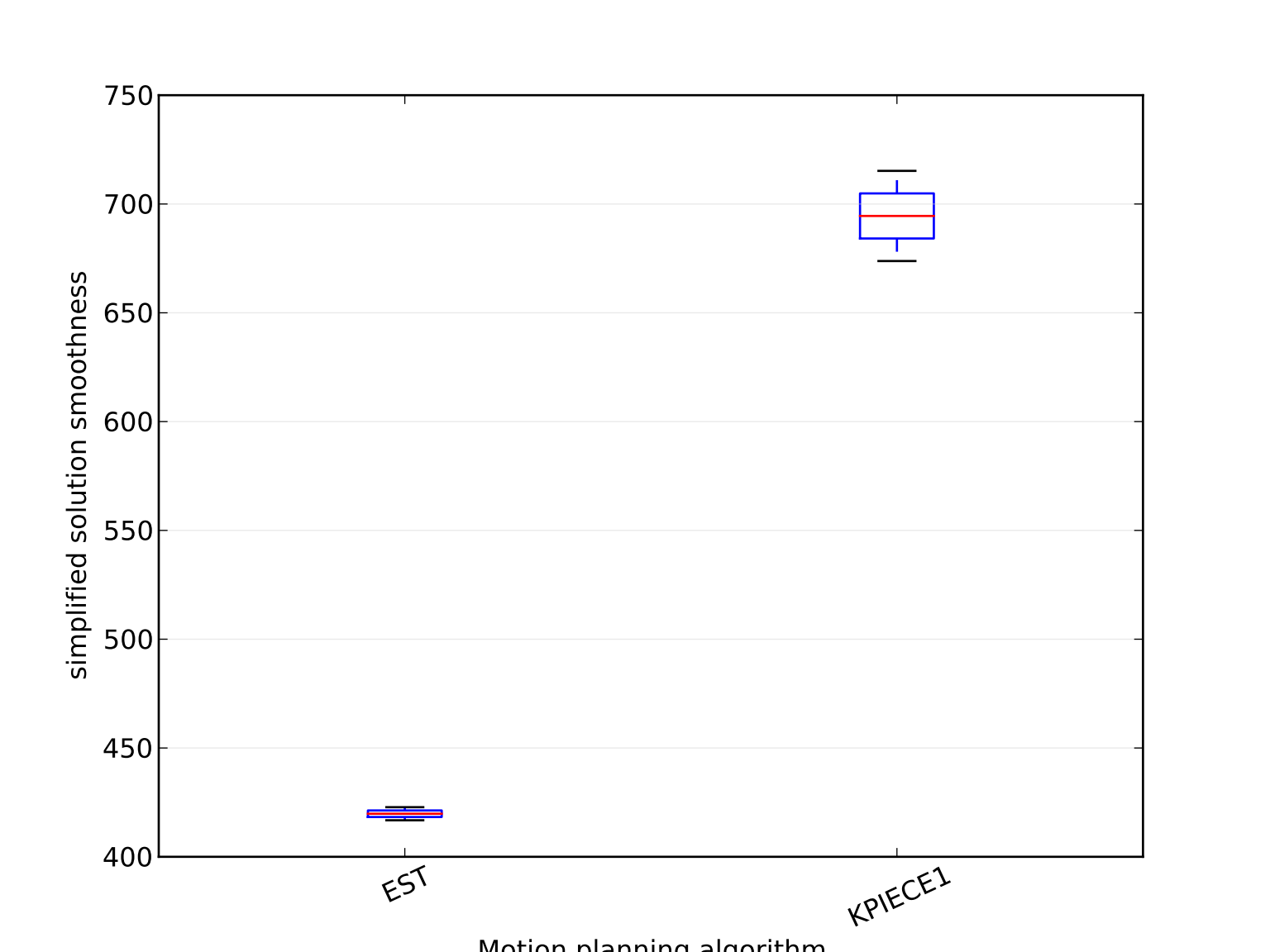

100
80
60
40
20
0
simplified correct solution (%)
EST
KPIECE1

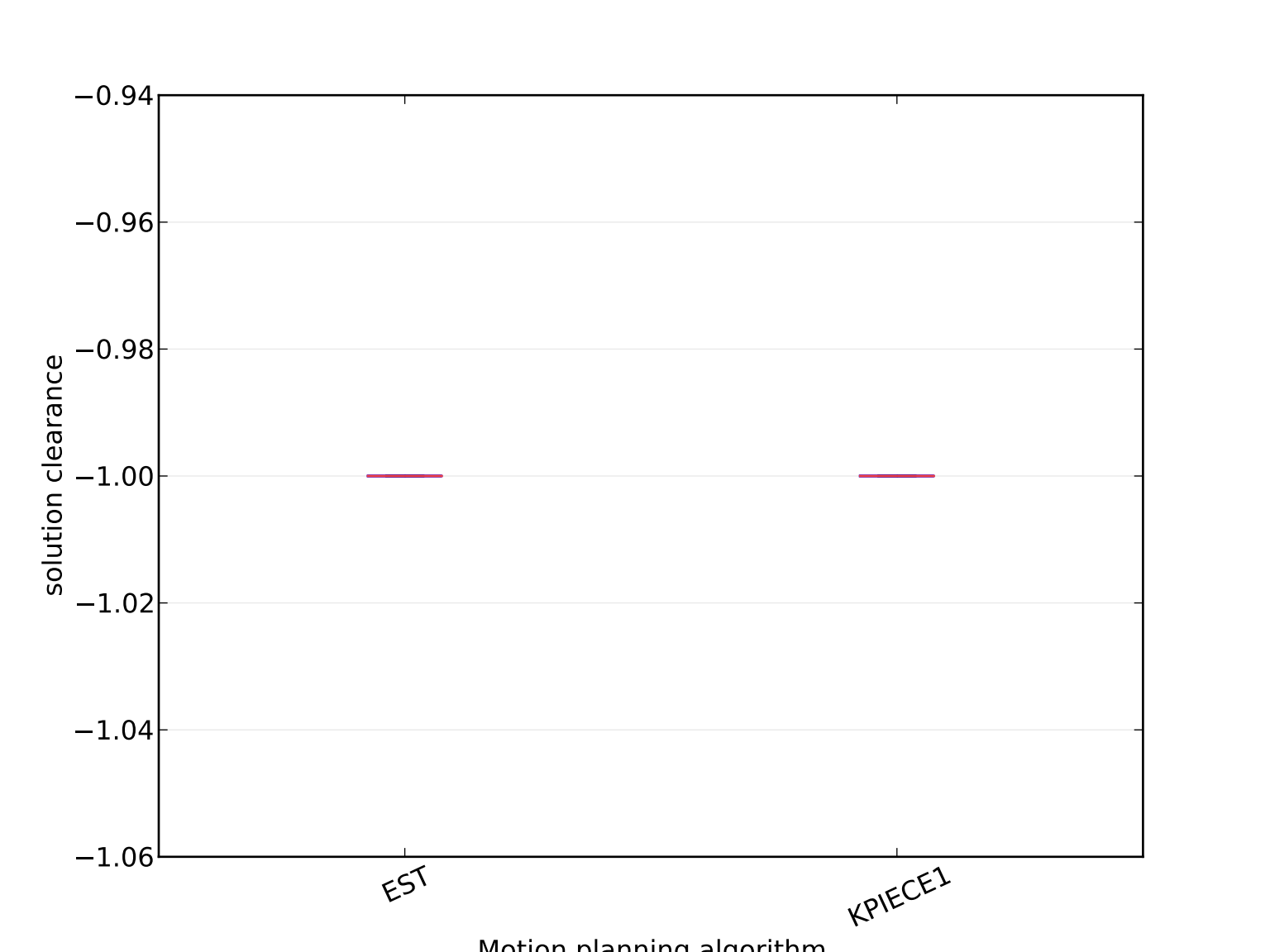

100
80
60
40
20
0
simplified correct solution strict (%)
EST
KPIECE1

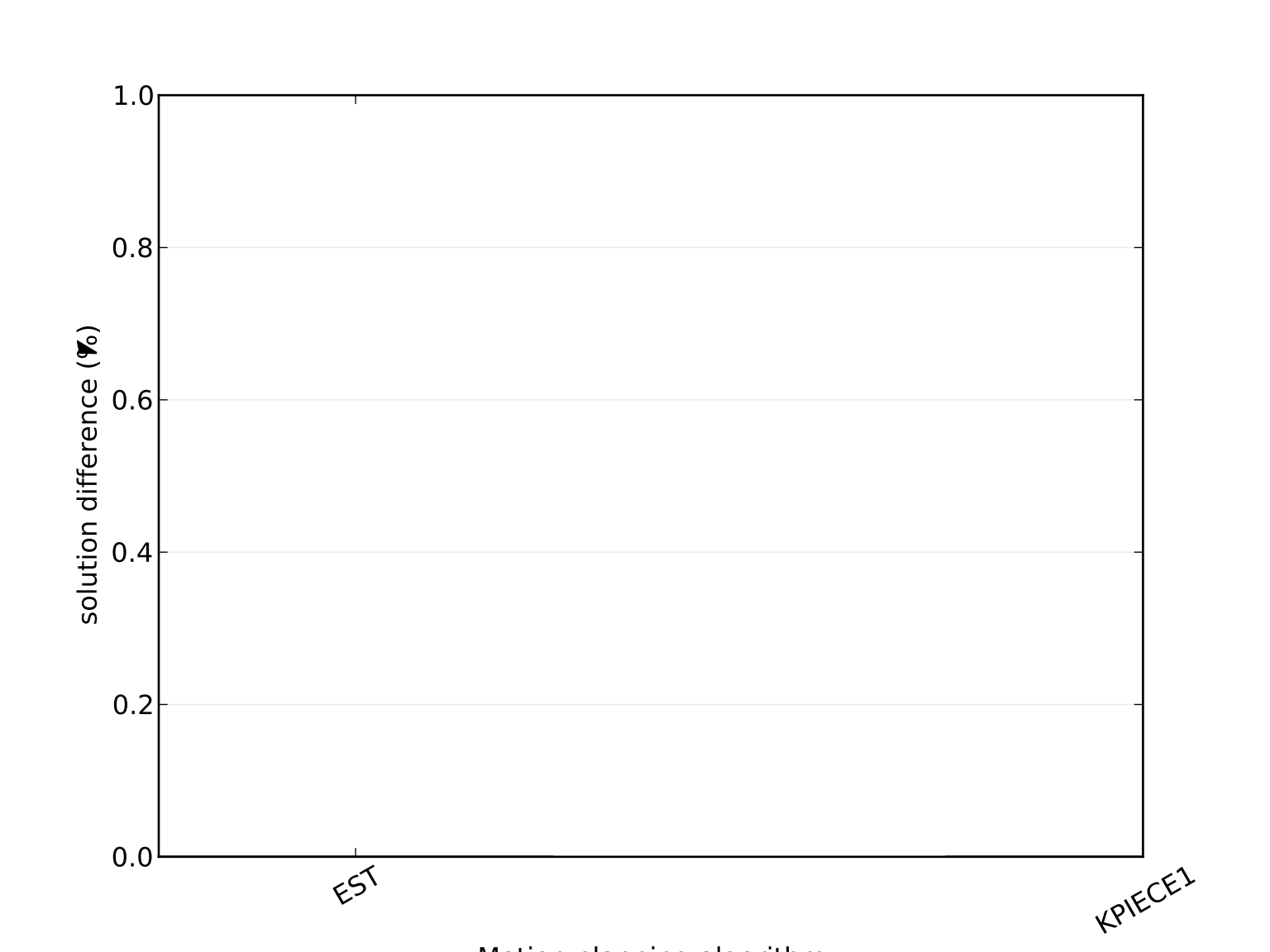

−0.94
−0.96
−0.98
−1.00
−1.02
−1.04
−1.06
simplified solution clearance
EST
KPIECE1
Motion planning algorithm

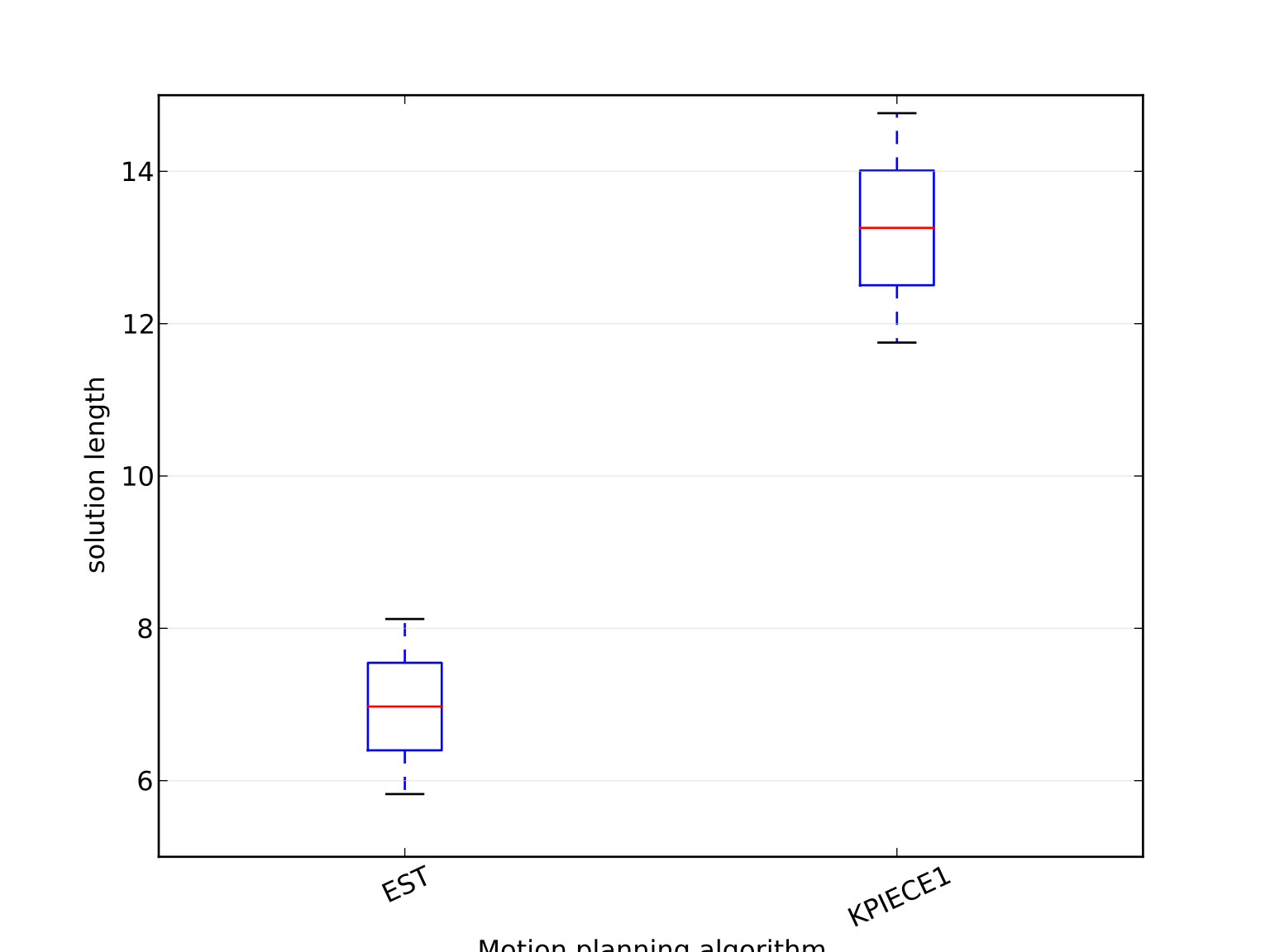

6.5
6.0
5.5
5.0
4.5
4.0
3.5
3.0
2.5
2.0
simplified solution length
EST
KPIECE1
Motion planning algorithm

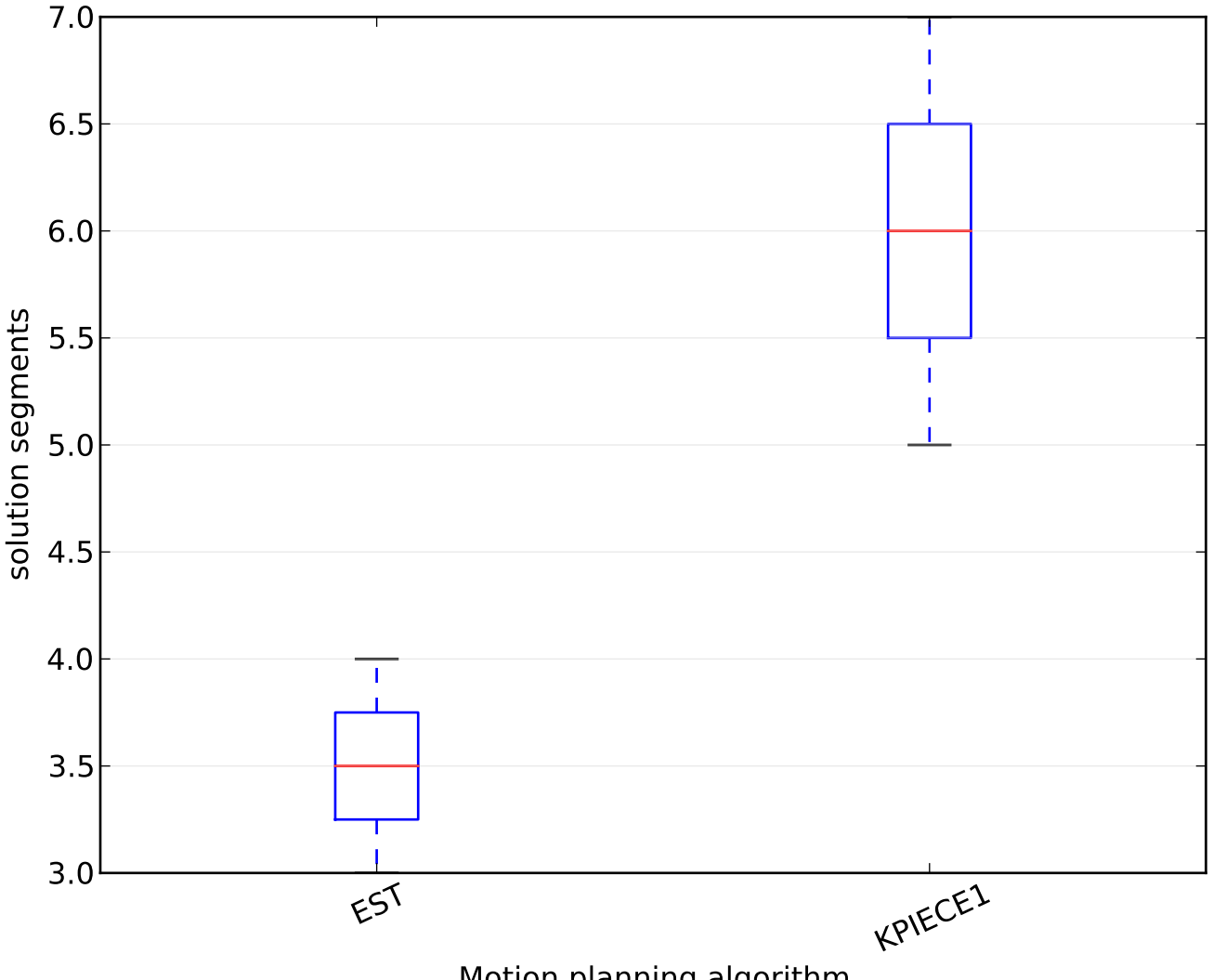

24
23
22
21
20
19
18
17
16
simplified solution segments
EST
KPIECE1
Motion planning algorithm

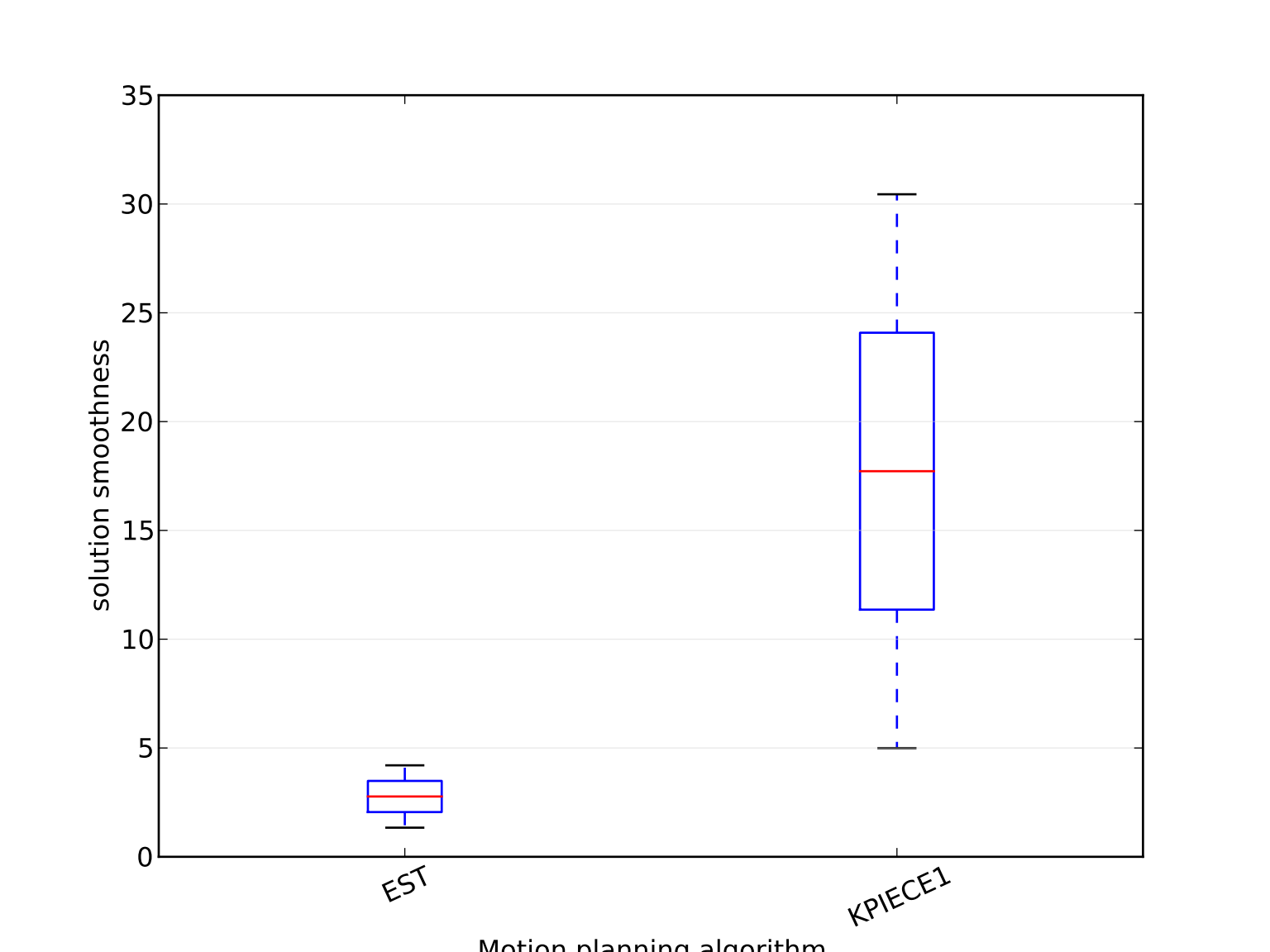

750
700
650
600
550
500
450
400
simplified solution smoothness
EST
KPIECE1
Motion planning algorithm

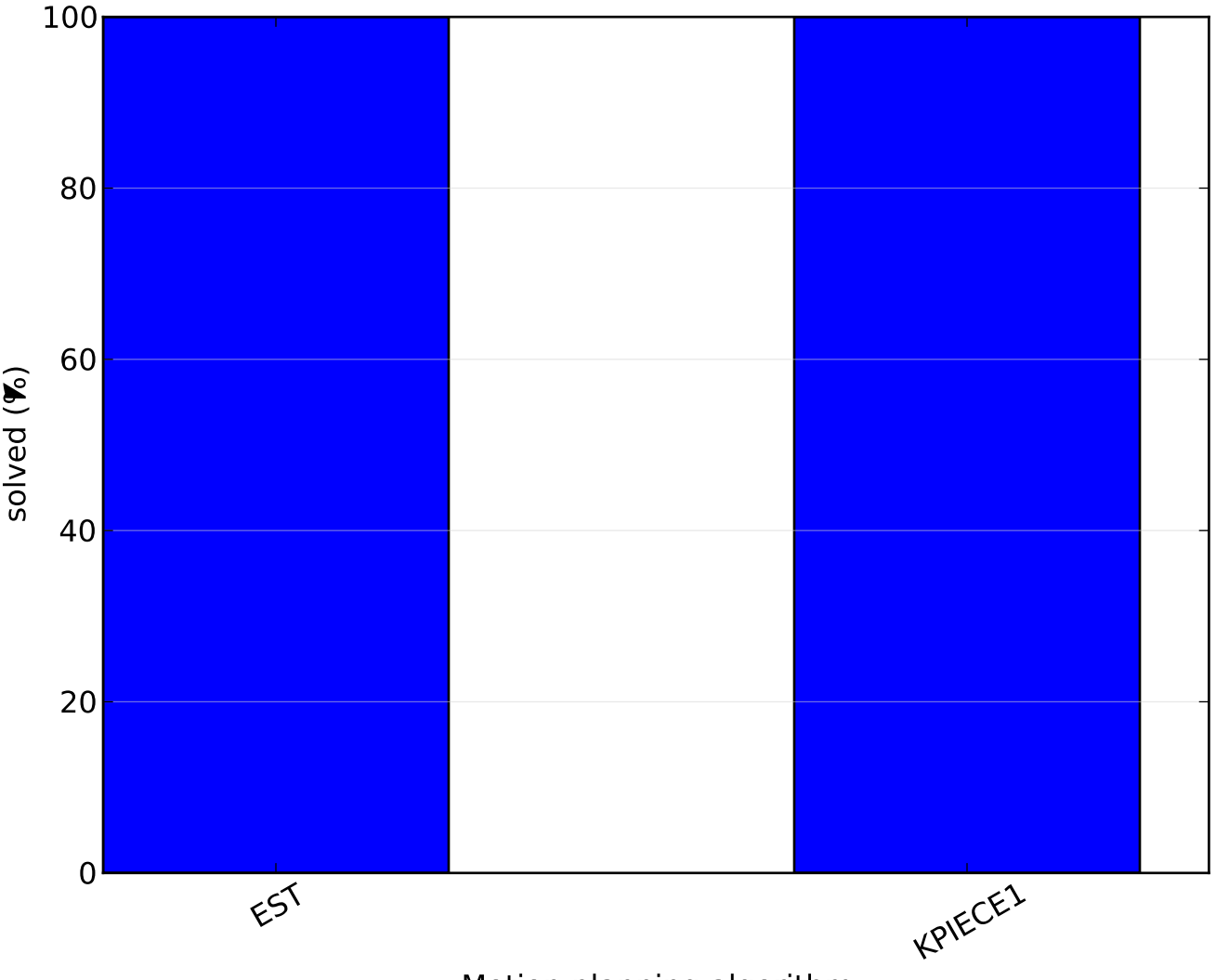

−0.94
−0.96
−0.98
−1.00
−1.02
−1.04
−1.06
solution clearance
EST
KPIECE1
Motion planning algorithm

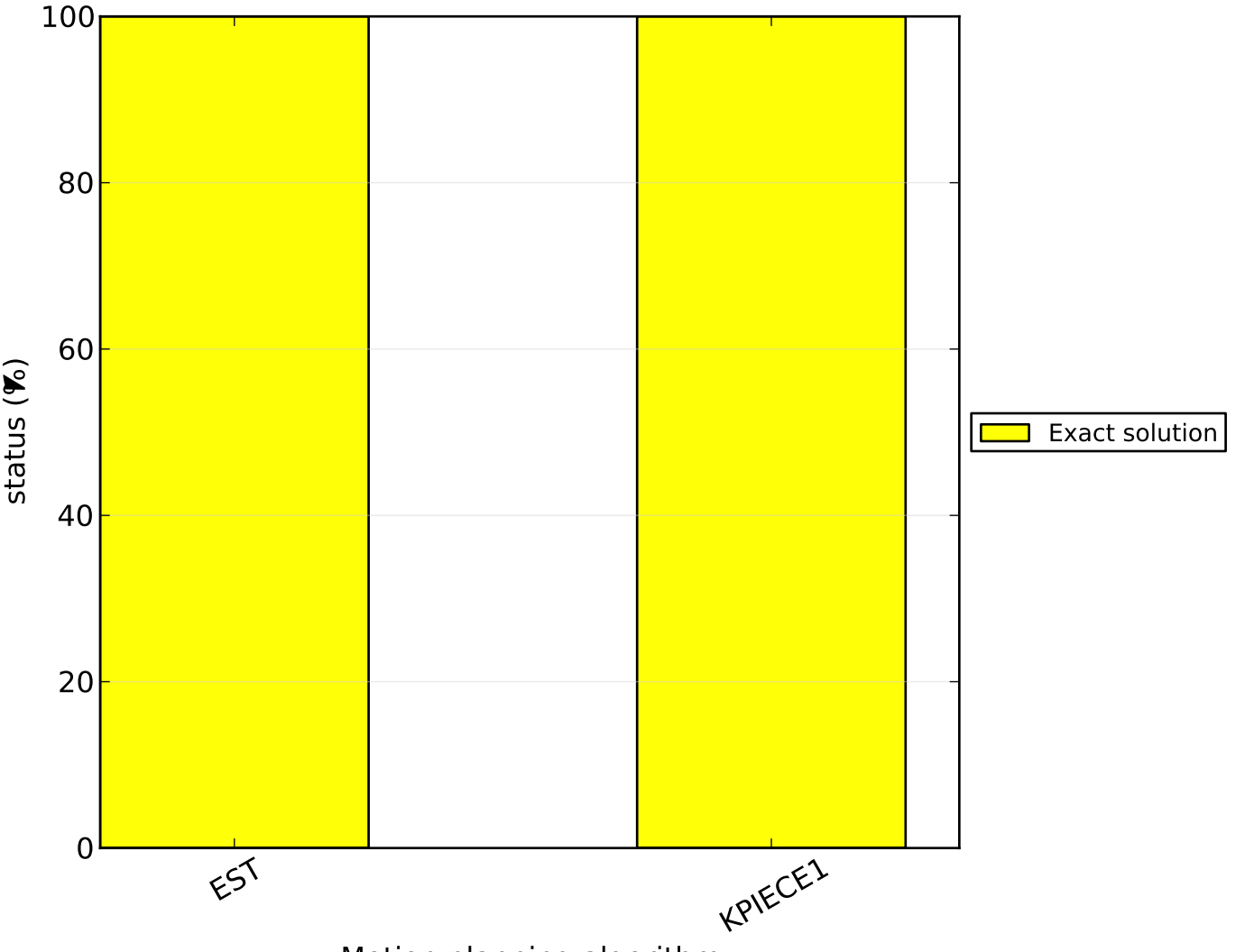

1.0
0.8
0.6
0.4
0.2
0.0
solution difference (%)
EST
KPIECE1

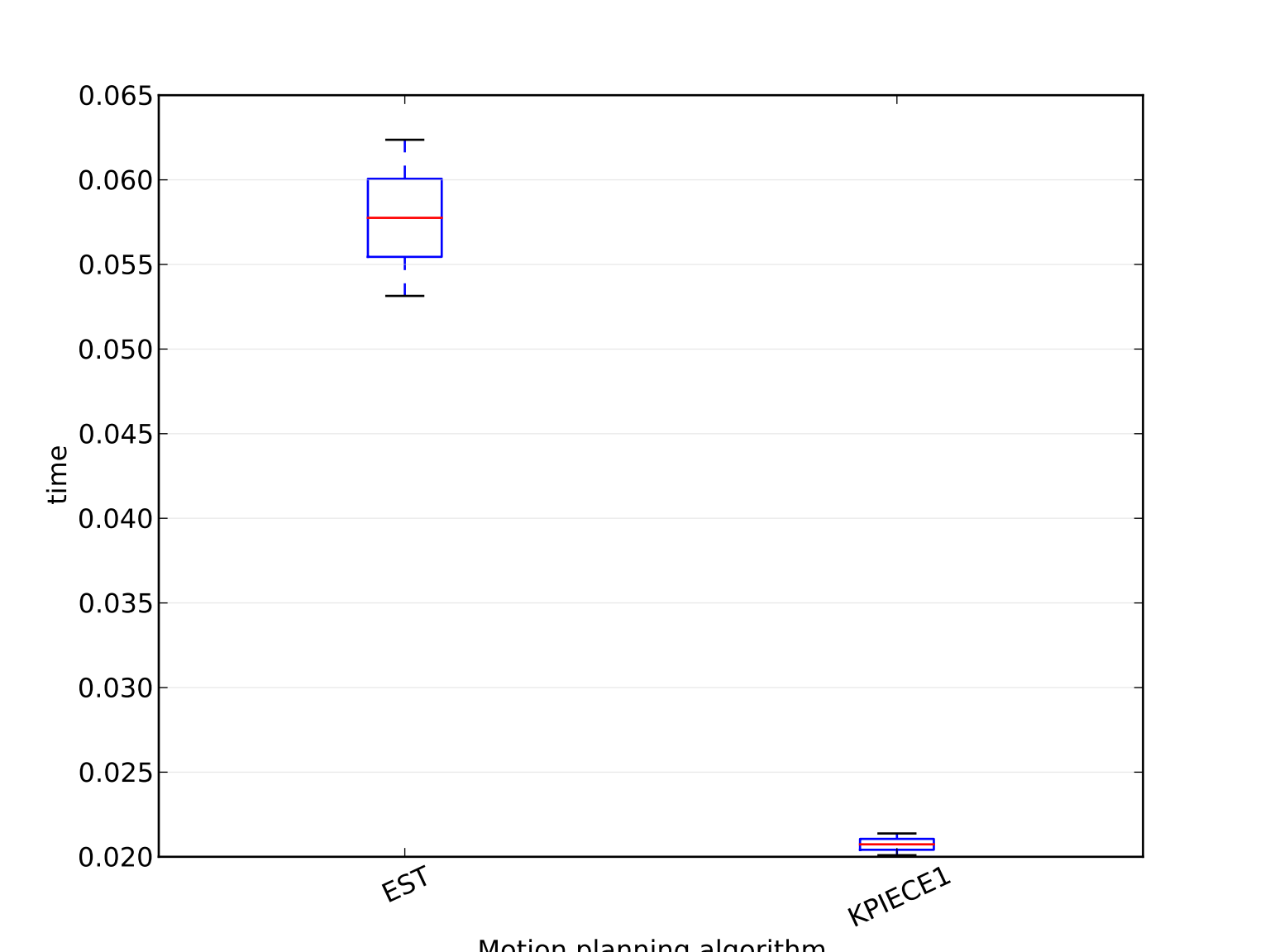

14
12
10
8
6
solution length
EST
KPIECE1
Motion planning algorithm

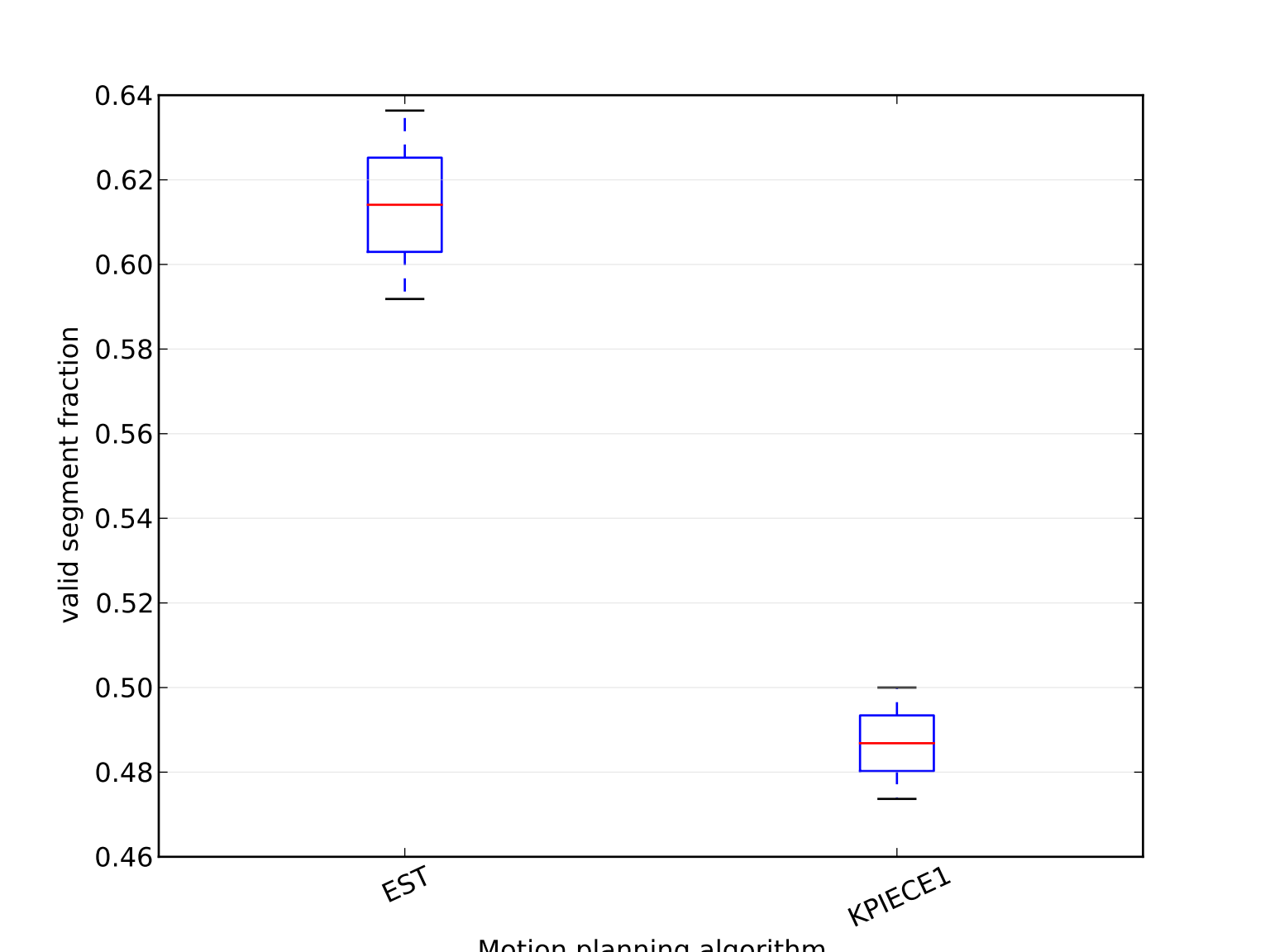

7.0
6.5
6.0
5.5
5.0
4.5
4.0
3.5
3.0
solution segments
EST
KPIECE1
Motion planning algorithm


35
30
25
20
15
10
5
0
solution smoothness
EST
KPIECE1
Motion planning algorithm


100
80
60
40
20
0
solved (%)
EST
KPIECE1


100
80
60
40
20
0
status (%)
EST
KPIECE1
Exact solution


0.065
0.060
0.055
0.050
0.045
0.040
0.035
0.030
0.025
0.020
time
EST
KPIECE1
Motion planning algorithm


0.64
0.62
0.60
0.58
0.56
0.54
0.52
0.50
0.48
0.46
valid segment fraction
EST
KPIECE1
Motion planning algorithm

Experiment 'experiment'

Number of averaged runs: 2

Time limit per run: 10.0 seconds

Memory limit per run: 100.0 MB